

RF04-S

Rotary type / Sensor specification

- CE compliance
- Limitless rotation

Ordering method

RF04-S

Model	Return-to-origin method S: Sensor (Limitless rotation)	Bearing N: Standard H: High rigidity	Torque N: Standard torque H: High torque	Cable entry location R: From the right L: From the left	Rotation direction N: CCW Z: CW	Cable length ^{Note 1} 1K: 1m 3K: 3m 5K: 5m 10K: 10m
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S2	Robot positioner S2: TS-S2 ^{Note 2}	I/O NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 3}
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SH	Robot positioner SH: TS-SH	I/O NP: NPN PN: PNP CC: CC-Link DN: DeviceNet™ EP: EtherNet/IP™ PT: PROFINET GW: No I/O board ^{Note 3}	Battery B: With battery (Absolute) N: None (Incremental)
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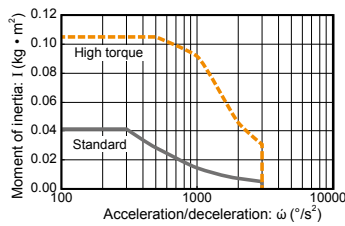
Note 1. The robot cable is flexible and resists bending.
 Note 2. See P.498 for DIN rail mounting bracket.
 Note 3. Select this selection when using the gateway function. For details, see P.60.

Basic specifications

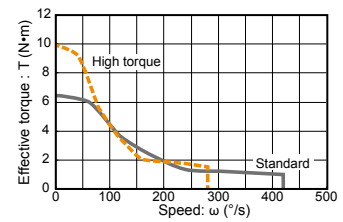
Motor	42 □ Step motor
Resolution (Pulse/rotation)	20480
Repeatability ^{Note 1} (°)	+/-0.05
Drive method	Special worm gear + belt
Torque type	Standard High torque
Maximum speed ^{Note 2} (°/sec)	420 280
Rotating torque (N•m)	6.6 10
Max. pushing torque (N•m)	3.3 5
Backlash (°)	+/-0.5
Max. moment of inertia ^{Note 3} (kg•m ²)	0.04 0.1
Cable length (m)	Standard: 1 / Option: 3, 5, 10
Rotation range (°)	360

Note 1. Positioning repeatability in one direction.
 Note 2. The maximum speed may vary depending on the moment of inertia. Check the maximum speed while referring to the "Moment of inertia vs. Acceleration/ deceleration" graph and the "Effective torque vs. speed" graph (reference).
 Note 3. For moment of inertia and effective torque details, see P.604.

Moment of inertia Acceleration/deceleration



Effective torque vs. speed



Allowable load

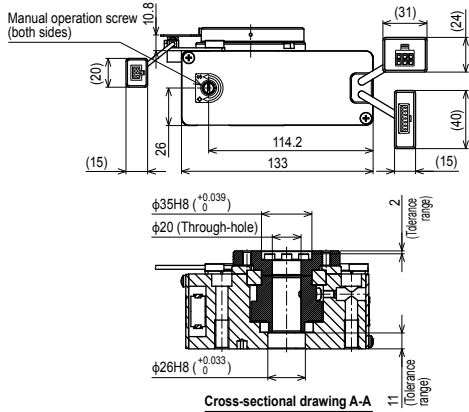
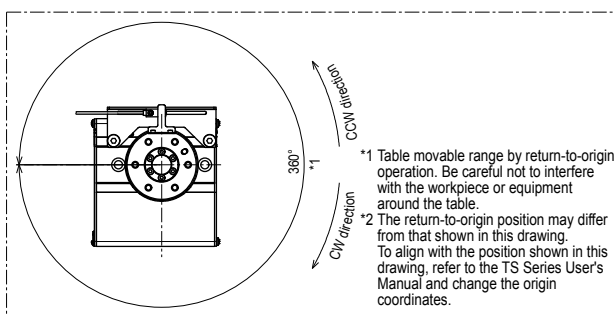
	(a)	(b)	
Allowable radial load (N)	Allowable thrust load (N)		Allowable moment (N•m)
Standard model	Standard model	Standard model	Standard model
High rigidity model	High rigidity model	High rigidity model	High rigidity model
314	296	398	9.7
378	517	12.0	

Controller

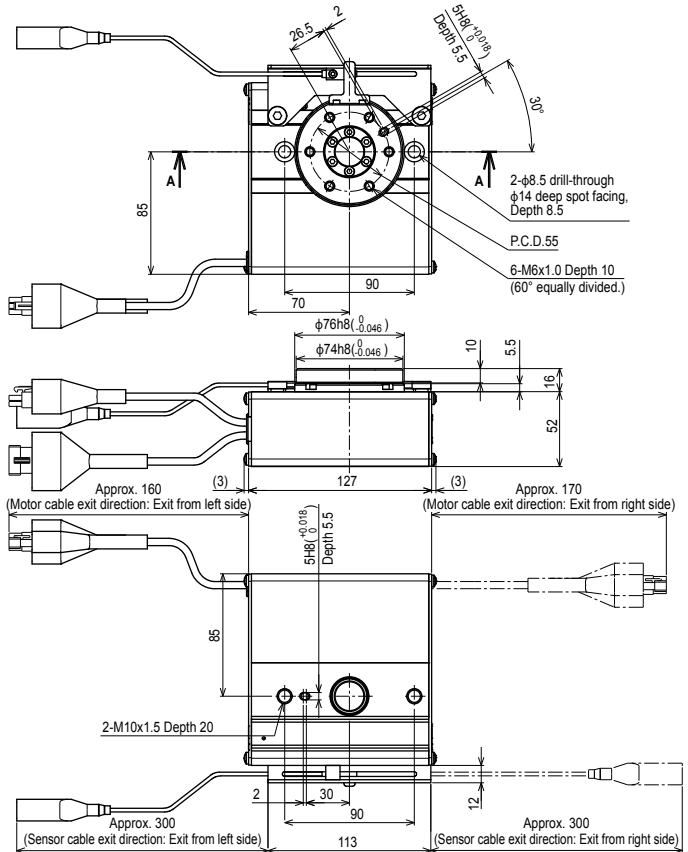
Controller	Operation method
TS-S2S	I/O point trace / Remote command
TS-SHS	Remote command

Note. When purchasing the product, set the controller acceleration while carefully checking the "Moment of inertia vs. Acceleration/Deceleration" and "Effective torque vs. Speed" graphs. For details, please refer to the TRANSERVO Series User's Manual.

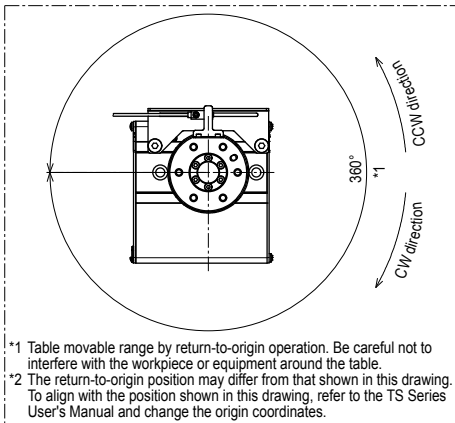
RF04-SN Sensor specification – Standard model



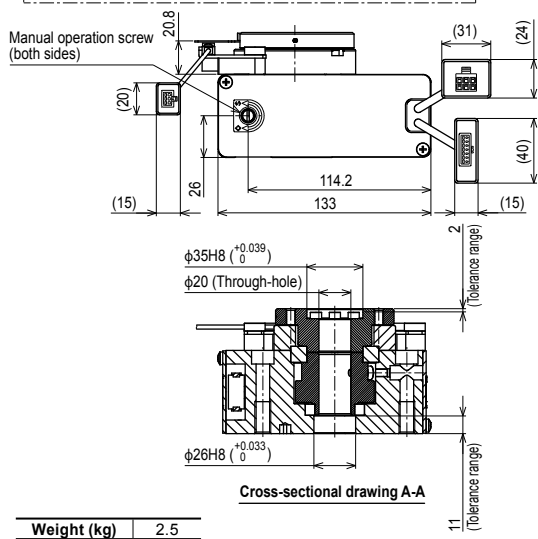
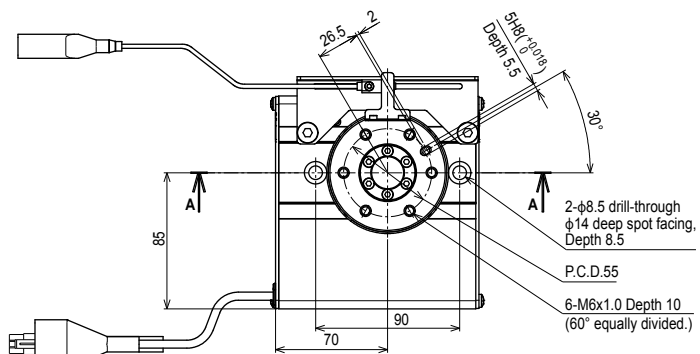
Note 1. This drawing is output under the conditions below.
 Bearing Standard
 Torque Standard/High torque
 Note 2. The minimum bending radii of the motor cable and sensor cable are R30.



RF04-SH Sensor specification – High rigidity model



*1 Table movable range by return-to-origin operation. Be careful not to interfere with the workpiece or equipment around the table.
*2 The return-to-origin position may differ from that shown in this drawing. To align with the position shown in this drawing, refer to the TS Series User's Manual and change the origin coordinates.



Weight (kg)	2.5
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Note 1. This drawing is output under the conditions below.
Bearing..... High rigidity
Torque..... Standard/High torque
Note 2. The minimum bending radii of the motor cable and sensor cable are R30.

